

Amendments to the Claims

1. (Withdrawn) A manufacturing cell for work pieces, comprising:
a device for machining a work piece,
one or more storage locations for fetching a work piece,
one or more storage locations for returning the work piece,
automated manipulating means for transfers of the work piece, which are arranged to grip the work piece, to place the work piece in the machining device and to deliver the machined work piece,
transfer means, which are arranged to transfer said manipulating means to and from said storage locations and said machining device, and
positioning means, wherein said manipulating means are arranged to deliver the work piece to said positioning means for setting the position of the work piece and for gripping it again after the setting,
wherein the positioning means are, together with the manipulating means, placed in said transfer means, or the positioning means are placed in separate transfer means, which are arranged to move said positioning means within the reach of the manipulating means at least for the time of said setting.
2. (Withdrawn) The manufacturing cell according to claim 1, wherein there are two or more positioning means of the same type.
3. (Withdrawn) The manufacturing cell according to claim 1, wherein separate transfer means are arranged to move the positioning means to a predetermined constant distance in relation to the manipulating means, if necessary, also during that transfer movement of the manipulating means which takes place simultaneously with the setting of the position of the work piece.
4. (Withdrawn) The manufacturing cell according to claim 1, wherein the machining device comprises an edging press or a press device intended for cutting or forming.

5. (Withdrawn) The manufacturing cell according to claim 1, wherein the storage location is a pallet, a platform or a conveyor, on which the work pieces are placed, wherein the work pieces are, for example, sheets or bent work pieces.
6. (Withdrawn) The manufacturing cell according to claim 1, wherein the manipulating means comprise a programmable robot.
7. (Withdrawn) The manufacturing cell according to claim 1, wherein the transfer means comprise a rail and a carriage moving back and forth along the rail, the manipulating means or the positioning means or both of them being placed on the carriage.
8. (Withdrawn) The manufacturing cell according to claim 1, wherein the positioning means comprise a support, along which the work piece is arranged to slide by the effect of gravity and to be placed in a desired position and location.
9. (Withdrawn) The manufacturing cell according to claim 8, wherein the positioning means also comprise sensor means, which are arranged to detect the adherence of several work pieces to each other.
10. (Withdrawn) The manufacturing cell according to claim 1, wherein the manipulating means comprise means for gripping work pieces, wherein they also comprise sensor means, which are arranged to detect the adherence of several work pieces to each other.
11. (Withdrawn) The manufacturing cell according to claim 1, wherein it also comprises sensor means, which are arranged to detect the adherence of several work pieces to each other by detecting the number of work pieces left in the storage location after the manipulating means have removed the work piece, to compare said number with the previous number.

12. (Currently amended) A transfer and manipulating apparatus for work pieces, comprising:

~~automated manipulating means~~ a programmable robot for transfers of a work piece, ~~which are said programmable robot being arranged to grip the work piece and to deliver the work piece again,~~

~~transfer means, which are arranged to transfer said manipulating means along a given path,~~ for transferring said programmable robot ~~work pieces~~ to different locations along a given path, and

positioning means for setting the position of the work piece,

~~wherein said manipulating means are~~ programmable robot is arranged to deliver the work piece to said positioning means ~~for setting the position of the work piece and for gripping, to grip the positioned work piece it again after the setting, and further to deliver the positioned work piece to a machining device,~~

~~wherein the positioning means, together with said programmable robot, are are, together with the manipulating means, placed in said transfer means, or the positioning means are placed in separate transfer means, which are arranged to move said positioning means within the reach of the manipulating means~~ said programmable robot at least for the time of ~~said setting~~ when the position of the work piece is set.

13. (Currently amended) The transfer and manipulating apparatus according to claim 12, wherein there are two or more of said ~~positioning means of the same type.~~

14. (Currently amended) The transfer and manipulating apparatus according to claim 12, wherein there is a plurality of transfer means, said separate transfer means each are arranged to keep ~~move~~ the positioning means to at a predetermined constant distance in relation to said programmable robot ~~the manipulating means, if necessary, also during that transfer movement of said programmable robot the manipulating meant which takes place simultaneously with the ceiling of the position of the work piece.~~

15. (Currently amended) The transfer and manipulating apparatus according to claim 12, wherein the positioning means ~~also~~ further comprises sensor means, which ~~are~~ is arranged to detect the adherence of several work pieces to each other.

16. (Currently amended) The transfer and manipulating apparatus according to claim 14, wherein the positioning means ~~also~~ further comprises sensor means, which are arranged to detect the adherence of several work pieces to each other.

17. (Withdrawn) A positioning device for work pieces, which is arranged to center a work piece in a given position and in a given location, when the workpiece is placed in said device for positioning, wherein the positioning device is also equipped with sensor means, which are arranged to detect the adherence of several work pieces to each other, one upon the other, and whose operation is possible simultaneously with either the arrival, the centering, the immobility, or exit of the work piece, wherein it is possible to avoid time delays caused by the detection in the work cycle.

18. (Withdrawn) The positioning device according to claim 17, wherein it comprises guides, along which the work piece is arranged to slide freely by the effect of gravity and to be guided to a given location and to a given position.

19. (Withdrawn) The positioning device according to claim 17, wherein said sensor means comprise a means which can be transferred against the work piece and which reaches a position, which can be used to determine, if there are one or more work pieces.

20. (Withdrawn) The positioning device according to claim 18, wherein said sensor means comprise a means which can be transferred against the work piece and which reaches a position, which can be used to determine, if there are one or more work pieces.

21. (Withdrawn) The positioning means according to claim 17, wherein said sensor means comprise optical means which are arranged to detect the side surfaces of work pieces placed next to each other, and if there are several work pieces placed in parallel.
22. (Withdrawn) The positioning means according to claim 18, wherein said sensor means comprise optical means which are arranged to detect the side surfaces of work pieces placed next to each other, and if there are several work pieces placed in parallel.
23. (Withdrawn) The positioning device according to claim 17, wherein it is placed in a stationary position, or fixed to transfer means which are arranged to move said positioning device along a desired path, or fixed in automated manipulating means which are arranged to deliver a work piece to said positioning device or to remove said work piece.
24. (New) The transfer and manipulating apparatus according to claim 12, wherein said machining device comprises a bending press or a press device adapted for cutting or forming.
25. (New) The transfer and manipulating apparatus according to claim 12, wherein the work piece is a metal sheet.
26. (New) The transfer and manipulating apparatus according to claim 12, wherein the positioning means comprises a support, along which the work piece is arranged to be moved by the effect of gravity and be placed in a desired position and location.
27. (New) A transfer and manipulating apparatus for work pieces, comprising:
an automated manipulator device arranged to grip, transfer and deliver a work piece,
a transfer device arranged to transfer said automated manipulator device along a given path to different locations, and

a positioning and centering device arranged for setting the position of the work piece,

wherein said automated manipulator device is arranged to deliver the work piece to said positioning and centering device, to grip the positioned work piece, and to deliver the positioned work piece to a machining device, and

wherein said positioning and centering device and said automated manipulator device are placed in said transfer device.

28. (New) The transfer and manipulating apparatus according to claim 27, wherein said automated manipulator device comprises a programmable robot.

29. (New) The transfer and manipulating apparatus according to claim 27, wherein said machining device comprises a bending press or a press device for cutting or forming.

30. (New) The transfer and manipulating apparatus according to claim 27, wherein the work piece is a metal sheet.

31. (New) The transfer and manipulating apparatus according to claim 27, wherein said automated manipulator device comprises a gripper for gripping the work piece, and wherein said positioning and centering device is separate from said gripper.

32. (New) The transfer and manipulating apparatus according to claim 27, wherein said automated manipulator device is arranged to fetch the work piece from a storage location.

33. (New) A transfer and manipulating apparatus for work pieces, comprising:
an automated manipulator device arranged to grip, transfer and deliver a work piece,

a transfer device arranged to transfer said automated manipulator device along a given path to different locations, and

a positioning and centering device arranged for setting the position of the work piece,

wherein said automated manipulator device is arranged to deliver the work piece to said positioning and centering device, to grip the positioned work piece, and to deliver the positioned work piece to a machining device, and

wherein said positioning and centering device is placed in another transfer device arranged to move said positioning and centering device within the reach of said automated manipulator device at least for the time when the position of the work piece is set.

34. (New) The transfer and manipulating apparatus according to claim 33. wherein said transfer device and said another transfer device are arranged to move along a common predetermined path.

35. (New) The transfer and manipulating apparatus according to claim 33, wherein said automated manipulator device comprises a programmable robot.

36. (New) The transfer and manipulating apparatus according to claim 33, wherein said machining device comprises a bending press or a press device for cutting or forming.

37. (New) The transfer and manipulating apparatus according to claim 33. wherein the work piece is a metal sheet.

38. (New) The transfer and manipulating apparatus according to claim 33. wherein said positioning and centering device comprises a support, along which the work piece is arranged to be moved by the effect of gravity and be placed in a desired position and location.